AMENDMENTS TO THE SPECIFICATION

Please amend paragraph [0061] on page 26, as follows:

The contact determination section 21 derives a height H_B from the ground to the bottom of the obstacle B, and compares the height H_B with a height H_A of the vehicle A (hereinafter, referred to as vehicle height data) stored in the data accumulating section 16 to be described below. Then, the contact determination section 21 determines whether the vehicle A can pass under the obstacle B, and generates a determination result J. In the present embodiment, when the height H_B is larger than the vehicle height data H_A, the contact determination section 21 ~~16~~ determines that the vehicle A can pass through. In this case, the determination result J is "J_T". On the other hand, when the height H_B is not larger than the vehicle height data H_A, the determination result J is "J_F".

Please amend paragraph [0062] on page 26, as follows:

The above contact determination section 21 ~~16~~ also typically includes a combination of the CPU, the ROM, and the RAM.

Please amend paragraph [0064] on page 27, as follows:

After step S11, the contact determination section 21 derives the height H_B from the ground to the bottom of the obstacle B shown in FIG. 14. The height H_B is obtained by substituting a distance C and an elevation angle φ, which are both currently stored in the RAM, and a height h of an adjacent active sensor 111 (included in mounting position data) into $H_B=h+D\cdot\sin\varphi$. Thereafter, the contact determination section 21 ~~16~~ compares the currently derived height H_B with the height data H_A of the vehicle A stored in the data accumulating section ~~16~~ 21. When the height H_B is larger, the contact determination section 16 determines that the vehicle A can pass under the obstacle B, and stores "J_T" in the RAM as the determination result J. On the other hand, when the height H_B is not larger, "J_F" is stored in the RAM as the determination result J (step S21).

Please amend paragraph [0070] on page 29, as follows:

The contact determination section 32 derives a predicted trajectory through which the vehicle A is intended to move based on the detected result outputted from the steering

angle sensor 31. Furthermore, the contact determination section 32 determines whether an obstacle B exists along the derived predicted trajectory based on a distance C and direction D, both stored in the RAM, between the vehicle A and the obstacle B. Thereafter, the contact determination section 32 generates a determination result K. In the present embodiment, when the obstacle B exists along the predicted trajectory, the contact determination section 32 stores "K_T" in the RAM as the determination result ~~J~~ K; and when no obstacle B exists along the predicted trajectory, "K_T" is stored in the RAM as the determination result K.

Please amend paragraph [0075] on page 30, as follows:

The aforementioned determination is performed based on whether a contact is likely to occur such that a driver can use the vehicle surrounding display device 1b in a situation, for example, where a vehicle is parked into a parking space, thus making it possible to provide the vehicle surrounding display device 1b ~~1a~~ having better usability.